

**IN THE ABSTRACT:**

The Abstract as amended below with a replacement Abstract shows added text with underlining and deleted text with ~~striketrough~~.

Please DELETE the Abstract in its entirety and substitute the attached new Abstract.

A workpiece is gripped by a robot hand and then an image of the workpiece is captured by a camera ~~without being stopped~~. An image processing device detects the position and posture of a characteristic portion of the workpiece. ~~A robot controller stores the present position of the robot once or more times synchronously with the output of an image pick-up trigger instruction.~~ On the basis of the present position of the robot ~~and a detection result~~, the relative position and posture between a flange of the robot and the workpiece characteristic portion is detected. The relative position and posture is compared with that observed when the workpiece is gripped correctly, to determine a gripping error. If the gripping error exceeds a permissible error, the robot is stopped. If the gripping error is equal to or less than the permissible error, a taught position where the workpiece is to be released is corrected so as to cancel the adverse effect of the gripping error.